

ABSTRACT

Under the condition of a large variation ΔT_m in motor torque demand T_m^* , the significant torque change may lead to some vibration of a vehicle to temporarily heighten an angular acceleration α . The temporary rise of the angular acceleration α may cause the angular acceleration α to exceed a preset threshold value α_{slip} and result in misdetection of the occurrence of a 'phantom' skid in an angular acceleration α - based skid state determination (step S112). The drive control of the invention accordingly specifies a potential for misdetection of the occurrence of a 'phantom' skid when the variation ΔT_m in motor torque demand T_m^* exceeds a preset threshold value T_{thr} at step S108. The drive control thereby does not execute skid occurring state control (step S120) with torque restriction but performs grip state control at step S116.